In the Claims:

Please amend the claims as follows:

1. (currently amended) A robot wrist for an industrial robot, said robot wrist ~~(8)~~ comprising a wrist housing ~~(9)~~ and a wrist part ~~(5)~~, here designated tilt, journalled at the wrist housing ~~(9)~~, wherein the tilt ~~(5)~~ is rotatable relative to the wrist housing ~~(9)~~ about an axis of rotation ~~(55)~~ and comprises a drive unit ~~(14)~~ comprising a motor ~~(16)~~ with a motor housing ~~(18)~~, ~~characterized in that~~ wherein a shell part ~~(20)~~ of the motor housing is designed to connect the tilt ~~(5)~~ to the wrist housing ~~(9)~~.

2. (currently amended) ~~A~~ The robot wrist according to claim 1, ~~characterized in that~~ wherein the tilt comprises a first part ~~(6a)~~ that is rotatable relative to the wrist housing ~~(9)~~ about a first axis of rotation ~~(55)~~, and a second part ~~(6b)~~ that is connected to the first part ~~(6a)~~ and designed to support a toolholder ~~(7)~~ or the like and that is rotatable relative to the first part ~~(6a)~~ about a second axis of rotation ~~(56)~~.

3. (currently amended) ~~A~~ The robot wrist according to claim 2, ~~characterized in that~~ wherein the drive unit ~~(14)~~ is arranged for rotation of the second part ~~(6b)~~ relative to the first part ~~(6a)~~ about the second axis of rotation ~~(56)~~.

4. (currently amended) ~~A~~ The robot wrist according to claim 1, wherein ~~1 or 2,~~ ~~characterized in that~~ the drive unit ~~(14)~~ is arranged for rotation of the tilt ~~(5)~~ relative to the wrist

housing ~~(9)~~.

5. (currently amended) ~~A~~ The robot wrist according to claim 1, wherein ~~any of the preceding claims, characterized in that~~ the outside of the shell part is designed to connect the tilt ~~(5)~~ to the wrist housing ~~(9)~~.

6. (currently amended) ~~A~~ The robot wrist according to claim 1, wherein ~~any of the preceding claims, characterized in that~~ the motor ~~(16)~~ comprises a stator ~~(22)~~ and a rotor ~~(21)~~ arranged in the motor housing ~~(18)~~, the shell part ~~(20)~~ being adapted to surround the stator ~~(22)~~.

7. (currently amended) ~~A~~ The robot wrist according to claim 6, ~~characterized in that~~ wherein the stator ~~(22)~~ makes contact with the shell part ~~(20)~~.

8. (currently amended) ~~A~~ The robot wrist according to claim 7, ~~characterized in that~~ wherein the stator ~~(22)~~ makes contact with the inside of the shell part.

9. (currently amended) ~~A~~ The robot wrist according to claim 8, ~~characterized in that~~ wherein the inside of the shell part comprises a shoulder ~~(24)~~, wherein the stator ~~(22)~~ makes contact with the shoulder ~~(24)~~ to prevent displacement of the stator ~~(22)~~ in an axial direction relative to the motor housing ~~(18)~~.

10. (currently amended) ~~A~~ The robot wrist according to claim 6, wherein ~~any of claims 6-9, characterized in that~~ the motor housing ~~(18)~~ comprises an opening ~~(23)~~ adapted to allow

insertion of the stator ~~(22)~~ into the motor housing, wherein the motor housing ~~(18)~~ comprises a sealing member ~~(26)~~ adapted to seal the opening ~~(23)~~.

11. (currently amended) ~~A~~ The robot wrist according to claim 10, ~~characterized in that~~ wherein the sealing member ~~(26)~~ comprises a front portion ~~(28)~~ adapted to be received inside the shell part ~~(20)~~.

12. (currently amended) ~~A~~ The robot wrist according to claim 9, wherein ~~claims 11 and 9, characterized in that~~ the stator ~~(22)~~ is clamped between the front portion ~~(28)~~ of the sealing member and the shoulder ~~(24)~~ of the shell part.

13. (currently amended) ~~A~~ The robot wrist according to claim 1, wherein ~~any of the preceding claims, characterized in that~~ the shell part ~~(20)~~ is provided on its outside with at least one fixing member ~~(30a, 30b)~~, which is rigidly connected to a corresponding fixing member ~~(12a, 12b)~~ in the wrist housing ~~(9)~~.

14. (currently amended) ~~A~~ The robot wrist according to claim 13, ~~characterized in that~~ wherein the fixing member ~~(30a, 30b)~~ of the shell part comprises a recess ~~(33)~~ and ~~that~~ wherein the fixing member ~~(12a, 12b)~~ of the wrist housing comprises a shaft journal ~~(13)~~ received in said recess, or vice versa.

15. (currently amended) ~~A~~ The robot wrist according to claim 13, wherein ~~13 or 14, characterized in that~~ a fixing member ~~(30A, 30B)~~ of the shell part and a corresponding fixing

member ~~(12a, 12b)~~ of the wrist housing ~~(9)~~ make contact with each other via mutual contact surfaces ~~(15, 35)~~, whereby these contact surfaces ~~(15, 35)~~ are provided with countersunk and/or raised portions adapted to engage with each other to transmit a rotary force between the fixing members.

16. (currently amended) ~~A~~ The robot wrist according to claim 13, wherein ~~any of claims 13-15, characterized in that~~ the shell part ~~(20)~~ is provided with two fixing members ~~(30A, 30B)~~ on essentially opposite sides of the shell part.

17. (currently amended) ~~A~~ The robot wrist according to claim 1, wherein ~~any of the preceding claims, characterized in that~~ the robot wrist ~~(8)~~ is designed for a maximum handling weight of at least 100 kg.

18. (currently amended) An industrial robot, ~~characterized in that~~ wherein the industrial robot comprises a robot wrist ~~(8)~~ according to ~~any of claims 1-17~~ claim 1.

19. (currently amended) A tilt intended to be journalled in a wrist housing of a robot wrist for an industrial robot, wherein the tilt ~~(5)~~ is rotatable relative to the wrist housing about an axis of rotation ~~(55)~~ and comprises a drive unit ~~(14)~~ comprising a motor ~~(16)~~ with a motor housing ~~(18)~~, ~~characterized in that~~ wherein a shell part ~~(20)~~ of the motor housing ~~(18)~~ is designed to connect the tilt ~~(5)~~ to the wrist housing.

20. (currently amended) ~~A~~ The tilt according to claim 19, ~~characterized in that~~ wherein

the tilt ~~(5)~~ comprises a first part ~~(6a)~~ that is rotatable relative to the wrist housing about a first axis of rotation, and a second part ~~(6b)~~ that is connected to the first part ~~(6a)~~ and is designed to support a toolholder ~~(7)~~ or the like and that is rotatable relative to the first part ~~(6a)~~ about a second axis of rotation ~~(56)~~.

21. (currently amended) ~~A~~ The tilt according to claim 20, ~~characterized in that~~ wherein the drive unit ~~(14)~~ is adapted for rotation of the second part ~~(6b)~~ relative to the first part ~~(6a)~~ about the second axis of rotation ~~(56)~~.

22. (currently amended) ~~A~~ The tilt according to claim 19, wherein ~~19 or 20, characterized in that~~ the drive unit ~~(14)~~ is adapted for rotation of the tilt ~~(5)~~ relative to the wrist housing.